

7. (New) A method according to claim 4, wherein step (c) includes determining the position of a centroid based on luminance of the selected object and applying the Kalman predictive algorithm to the centroid.

8. (New) A method according to claim 4, wherein each image frame is resolved into multiple blocks and step (a) comprises segmenting the initial frame based on color of the blocks.

9. (New) A method according to claim 8, wherein step (b) includes identifying a color model to which the selected object belongs and step (c) includes:

predicting the position of a centroid of the selected object in a subsequent frame,

determining whether the predicted position of the centroid in said subsequent frame is within a boundary of the selected object in said subsequent frame,

and, in the event that the predicted position of the centroid in said subsequent frame is not within the boundary of the selected object in said subsequent frame, carrying out a search to identify a block that belongs to the selected color model.

10. (New) A method according to claim 4, wherein each image frame is resolved into multiple blocks and step (c) comprises:

determining position and velocity of a centroid of the selected object in the initial frame,

predicting the position of the centroid in a subsequent frame, from the predicted position of the centroid in said subsequent frame, extracting a connected group of blocks in said subsequent frame that belong to the selected object, and

calculating the position of the centroid of the selected object in said subsequent frame from the connected group of blocks.

REMARKS

The objections to the drawings identified in the Notice of Patent Drawing Review have been noted. Formal drawings avoiding these objections are submitted herewith.

Claim 1 stands rejected under 35 USC 103 over Schuster et al in view of Graham et al and claims 2 and 3 stand rejected under 35 USC 103 over Schuster et al in view of Graham et al as applied to